REMARKS/ARGUMENTS

Reconsideration of the subject application in view of present amendment is respectfully requested.

By the present amendment the independent claims 1 and 42 are amended to distinguish the present invention over the references cited within the Office action. Also, the Abstract is amended as required within the Office action.

Independent claims 1 and 42 respectively now state:
"and that said sensing system (11,12,13) synchronizes the time intervals (28,29) within which the system (11,12,13) detects magnetic fields based on the properties of said first current pulse (20), said first current pulse being transmitted through an electrical cable (1) that substantially demarcates the area within which the automatic device (2) intends to operate"

"and that said sensing system (11,12,13) synchronize the time intervals (28,29) within which the system (11,12,13) detects magnetic fields based on the properties of said first current pulse (20), said first current pulse being transmitted through an electrical cable (1) that substantially demarcates the area within which the automatic device (2) intends to operate"

With regard to Peless (WO 99/59042), the document is directed to a robot that has an internal navigation system for systematic movement within the area to be treated. Thus, the Peless robot must therefore initially be placed closed to the extreme edge of the boundary. A wave generator 62 provides one pulse 66 for the boundary and one 68 for the obstacle. Each of the signals is provided into its respective wire (page 9, line 16).

Turning to the discussion set forth on page 9 of Peless, there is only a little information provide. It seems that the magnetic sensors only detect the signals when approaching the wires. This is indicated for instance at page 7, lines 21 – 23 where it is explained about the robot having a navigation system only knowing its absolute position. Reading the following lines on page 8 it is said that the robot turns 180 degrees when encountering the boundary. In the second paragraph it is clearly stated that the robot between boundary markers counts the number of laps to define the scan to use. This means that the signals are most likely of low power.

Peless does not indicate from where the synchronization signal 64 is provided. Most likely it is transmitted directly from the wave generator 62. The reason is that the robot has to detect the synchronization signal everywhere within the area it operates to avoid losing contact. Since the other signals most likely have low power, it would not be sufficient to provide the synchronization signal in the same way.

It is worth noting that the corresponding European patent application had been granted in view of similar amendments that were directed to the Peless document.

Thus it is believed that the claims as amended clearly define over the Peless document, either alone or in combination with the other cited documents.

If there are any additional fees resulting from this communication, please charge same to our Deposit Account No. 16-0820, our Order No. ABE1-37203.

Respectfully submitted,
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